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Insofar as the rejection original claims 12-22 under 35 U.S.C. §102 might be applied to claims 23-32 consideration of the following is requested. All of the prior 2s have been cancelled and new claims 23-32 have been added. New Claim 23 includes the features of previous claims 12 and 13. Previous claims 14 to 22 correspond in substance to claim 24 and 32 and references therein have been updated.

More specifically, Claim 23 includes the feature of previous claim 13, which includes that the means (40, 46) for applying a traction force on the object is arranged for co-operation with the molding tool (30,44) for applying the traction force on the object. For a better understanding, reference is made to previous claims 13 to 15 as well as Figs 4 and 5, and page 12, lines 1 to 18 and page 13, lines 11 to 26, wherein embodiments of the means (40, 46) for applying the traction force are described.

In one embodiment, the means (40) is arranged as one or a plurality of protruding elements of the body (39) (see page 12, lines 1 to 18). The protruding elements are arranged for co-operation with ejector return members (35) of the molding tool (30), the ejector return members are located on a movable part, wherein the ejector members can apply a force to the elements (40) and thereby the ejectors (35) apply a force to the elements (40) and also to the body (39) in a direction away from the molding tool (30). In this way a traction force is provided on the object.

In another embodiment, the means (46) is arranged as push-away members (46) adapted to bear on the molding tool and to apply a force between the molding

tool and the device for removing an object from a molding tool (previous claim 15; page 13, lines 11 to 26).

Advantages of providing the device for removing an object from a molding tool with such means (40,46) for applying a traction force on the object are discussed below.

In the Office Action the following document were referred to: GB 2 010 731, hereinafter referred to as D1. D1 discloses a device for removing ceramic moldings from an injection-molding machine having two mould halves. The device comprises a gripper and means to move the gripper to and from a position in which it can engage a molding held in one of the mould halves when the moulds is opened. The gripper has an air permeable contact surface shaped matchingly to engage at least part of the exposed surface of such a molding. Means for providing suction through the contact surface is also provided as well as a voltage source for easy release from the mould half minimizing the risk of damage of the molding (e.g. see page 1, lines 39 to 74, and claim 1).

D1 does not disclose a device according to new claim 23, in particular wherein means (40, 46) for applying traction force on the object is arranged for co-operation with the molding tool (30,44) for applying the traction force on the object.

Accordingly, the device as claimed in claim 23 is novel in view of D1.

Starting from D1, the technical problem is to provide a device for removing a molding object from a molding tool, wherein a sufficient traction force on the object to separate the object from the molding tool may be provided without any risk of damaging the object.

The solution according to the invention as claimed in claim 23 is to provide the means (40, 46) for applying a traction force on the object is arranged for co-operation with the molding tool (30,44) for applying the traction force on the object.

The means (40, 46) for applying a traction force on the object according to claim 23 provides the possibility of achieving a sufficient traction force on the object so as to separate the object from the molding tool after injection molding, wherein the object is made of plastics, for example. It should be noted that the means as shown in Figs 1 to 3 of the present application in form of the handling member (20; robot) as well as the means to move the gripper as disclosed in D1 would not provide a sufficient traction force to separate a plastic object from an injection molding tool. Thus, the invention as claimed in claim 23 provides an advantage over the device of D1.

The solution according to the invention is not disclosed in D1. D1 only describes a device as discussed above, wherein the gripper and the means to move the gripper provides a sufficient and suitable traction force for separating a ceramic molding from an injection molding tool. As indicated above, such means for moving the gripper resembles the means as shown in Figs 1 to 3 of the present application in form of the handling member (20; robot).

D1 does not give any indication of the possibility to have other means of providing the traction force than the means to move the gripper. In fact, D1 discloses that there is a risk that the ceramic moldings may partially be pulled off the mould tool (page 1, lines 66 to 69), when applying a traction force. D1 provides a solution to this problem, wherein a direct-voltage source is used for easy release of the moldings from the molding tool, and thereby less traction force is needed minimizing the risk of damages of the ceramic moldings. Thus, D1 teaches that the solution is to reduce the retaining force between the moldings and molding tool rather than increasing the traction force on the moldings (object).

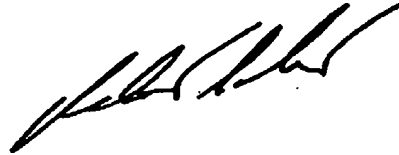
Based on the teaching of D1, it has not been demonstrated that the skilled person in view of D1 had the knowledge of the claimed invention and it has not been demonstrated that the skilled person would modify the device of D1 so as to arrive at the invention as defined in claim 23.

Accordingly, the device according to claim 23 presents an inventive step in view of D1.

Accordingly, it is submitted that the application is in condition for allowance and such action is requested. This response includes a petition for a 3 month time extension to respond and a credit card payment form.

Respectfully submitted,

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I hereby certify that this paper is being transmitted to the United States Patent and Trademark Office on January 26, 2007.



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